**This listing of claims replaces all prior versions, and listings, of claims in this application.**

**Listing of Claims:**

1. (Canceled)

2. (Previously Amended) The method according to Claim 17, wherein the gripping mechanism is arranged on the robot unit in such a way that a further horizontal motion, which overlays transfer along the horizontal beam, can be achieved.

3. (Currently Amended) The method according to Claim 17, wherein the gripping mechanism is arranged with at least two grip units, a first grip unit collecting the work object in an end situation and a second grip unit depositing the work object in another end situation, each of the first and second gripping units capable of collecting and placing objects simultaneously with the other unit, and wherein an intermediate storage for change of place of the work object is effected before it is transferred from the one end situation to the other end situation.

4. (Withdrawn) Method according to Claim 3, characterized in that the said device for intermediate storage (16) is arranged movably in at least the horizontal direction in the same direction in which the main horizontal transfer of the robot unit is effected.

5. (Previously Amended) The method according to Claim 17, wherein the pre-programmed path is programmed by an operator's actually transferring the gripping mechanism through a work cycle, and wherein successive registration of desired values is programmed in with respect to the rotor units forming part of the said motors, so that the control computer, through communication with a registration unit, can subsequently ensure automatic operation.

6. (Currently Amended) The robot unit for realizing the process according to Claim 17 comprising:

a first beam unit extending between two end points and the first and ~~a~~ the second workstation, wherein the first beam unit is the essentially horizontally extending beam;

a slide which is arranged movably along the first beam unit;

a second beam unit which extends essentially perpendicular to the first beam unit and which is arranged movably on the slide;

the gripping mechanism arranged on one end of the second beam unit, wherein the gripping mechanism includes a first and a second gripping unit, the units capable of simultaneously picking up separate objects; and

the at least two drive motors, which are connected to the control unit, a number of deflection rollers, and the belt member,

wherein the belt member is in the form of a single continuous drive belt which runs around the drive wheels of the drive motors and the deflection rollers and is fastened to the one end of the second beam unit, and

wherein the gripping mechanism reaches end points placed beyond the two end points of the horizontal beam, and

wherein the control unit is connected to an operator panel through which the control computer in the control unit can continuously be re-programmed by manually controlling the gripping mechanism to move into chosen situations.

7. (Previously Amended) The robot unit according to Claim 6, wherein the gripping mechanism comprises an elongated member.

8. (Currently Amended) The robot unit according to Claim 7, wherein the elongated member, at its one end, is arranged with ~~a~~ the first gripping unit ~~mechanism element~~ and, at its other end, is arranged with the ~~a~~ second gripping unit ~~mechanism element~~, the elongated member extending in the same longitudinal direction as the said first beam unit, such that the elongated member can simultaneously pick a first object at its one end and a second object at its other end.

9. (Previously presented) The robot unit according to Claim 6, wherein, between the first and second workstation, an intermediate table is arranged for intermediate storage of the work object.

10. (Withdrawn) Robot unit according to Claim 9, characterized in that the said intermediate table is arranged movably in relation to the said workstation (3, 4).

11. (Withdrawn) Robot unit according to Claim 7, characterized in that the said gripping mechanism (12C) is arranged movably in relation to the said elongated member (12D).

12. (Withdrawn) Robot unit according to Claim 11, characterized in that the said movable gripping mechanism unit (12C) is moved by means of retardation forces along the said beam unit (12D).

13. (Withdrawn) Robot unit according to Claim 11, characterized in that the said displaceable gripping mechanism unit (12C) is forcibly displaced along the said beam unit (12C) by means of

a drive belt (29) driven by a drive wheel (31) which is physically connected to any of the said deflection rollers (28, 30).

14. (Withdrawn) Robot unit according to Claim 10, characterized in that an upward-facing and downward-facing robot unit (10A) is mounted beneath the first robot unit (10), which upward-facing and downward-facing robot unit (10A) constitutes an intermediate storage table (16C) for the said first robot unit.

15. (Withdrawn) Robot unit according to claim 1, characterized by a further drive belt (36), which is drivably connected to a transmission (39) on the lower end (22A) of the vertical beam (22), in order to be able to perform further motion with the gripping mechanism (12).

16. (Withdrawn) Robot unit according to Claim, characterized in that the said belt (36) is driven by a drive wheel (37) connected to one of the said deflection rollers (30A).

17. (Previously Added) A method for rapidly transferring a work object in both horizontal and vertical directions, the method comprising:

providing a robot unit having a gripping mechanism;

providing a first workstation and a second workstation between which to transfer the work object, the work object weighing between one kilo and forty kilos, and the transfer in the horizontal direction being at least one meter but less than ten meters and at least partially being effected along an essentially horizontally extending beam;

arranging the gripping mechanism such that, at least in a first end situation along the beam, the gripping mechanism can collect the work object in a first position situated beyond the first end situation along the beam,

controlling the robot unit with a control unit;

driving the robot unit with a belt member and at least two motors having rotor units connected to drive wheels for the belt member;

immovably arranging the at least two motors in relation to the first and second workstations;

effecting transfer of the work object without displacement of either of the at least two motors;

executing the entire transfer of the work object along the beam;

providing the belt member as a single continuous drive belt, which, at the same time, is connected to and driven by the drive wheels; and

guiding the transfer of the work object along a pre-programmed path using a control computer in the control unit, through continuous control and registration of the situation of each of the rotor units of the motors.